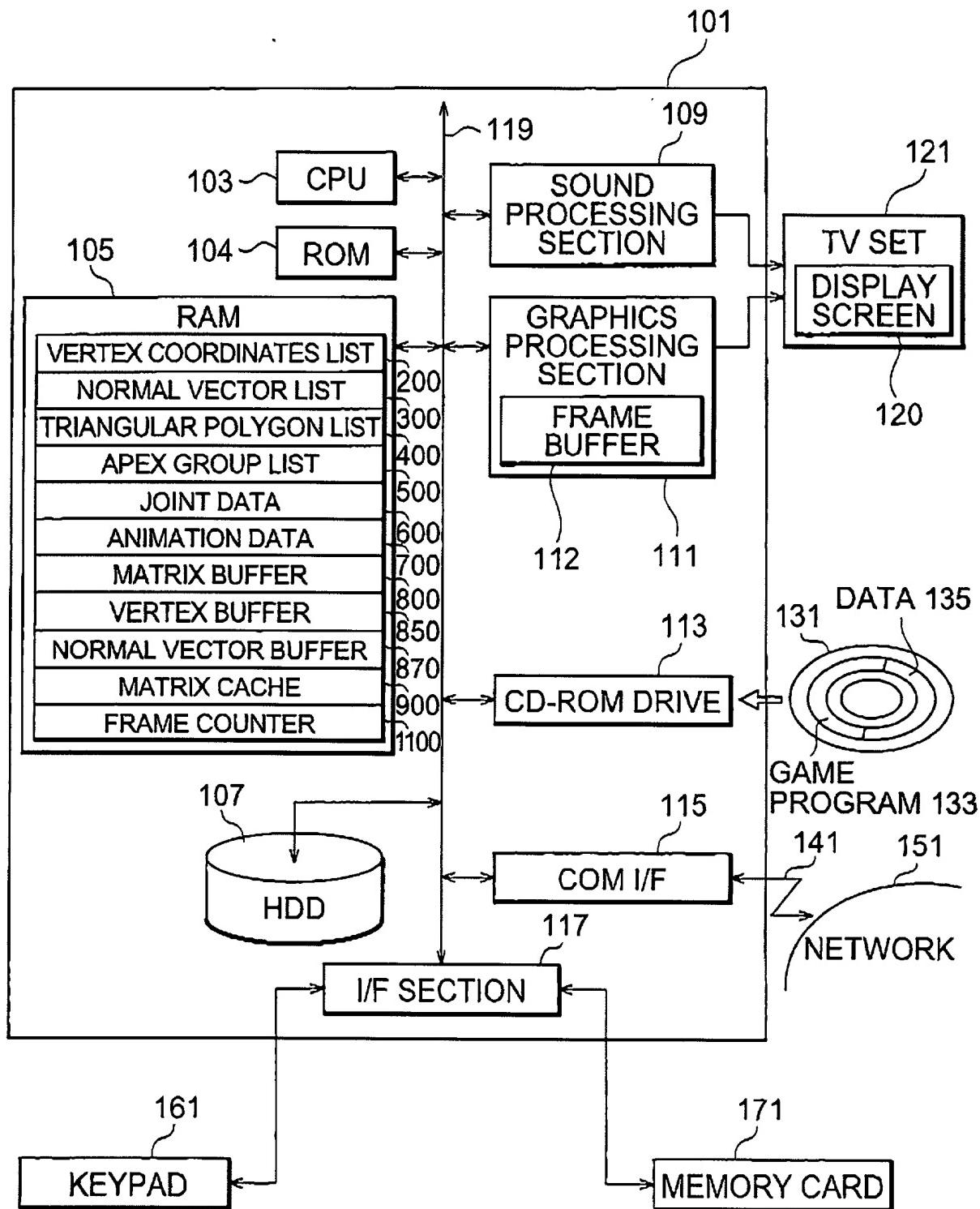


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Fig.1

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Fig.2

Diagram illustrating Fig.2: A table of vertex coordinates (vtx0-vtx4) with their corresponding indices (210, 220) pointing to the first column, and a pointer (200) pointing to the header row.

INDEX	COORDINATES (x,y,z)
vtx0	(0, 0, 0)
vtx1	(0, 0, 100)
vtx2	(0, 100, 0)
vtx3	(0, 100, 100)
vtx4	(100, 0, 0)
⋮	⋮

Fig.3

Diagram illustrating Fig.3: A table of normal vectors (nml0-nml4) with their corresponding indices (310, 320) pointing to the first column, and a pointer (300) pointing to the header row.

INDEX	NORMAL VECTOR (x,y,z)
nml0	(1, 0, 0)
nml1	(-1, 0, 0)
nml2	(0, 0, -1)
nml3	(-1, -1, 0)
nml4	(0, -1, 0)
⋮	⋮

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Fig.4

400

INDEX	VERTEX 0	VERTEX 1	VERTEX 2
plg0	vtx0 / nml0	vtx1 / nml2	vtx2 / nml3
plg1	vtx0 / nml1	vtx2 / nml3	vtx3 / nml4
⋮	⋮	⋮	⋮
⋮	⋮	⋮	⋮
⋮	⋮	⋮	⋮

Fig.5

500

VERTEX GROUP LIST

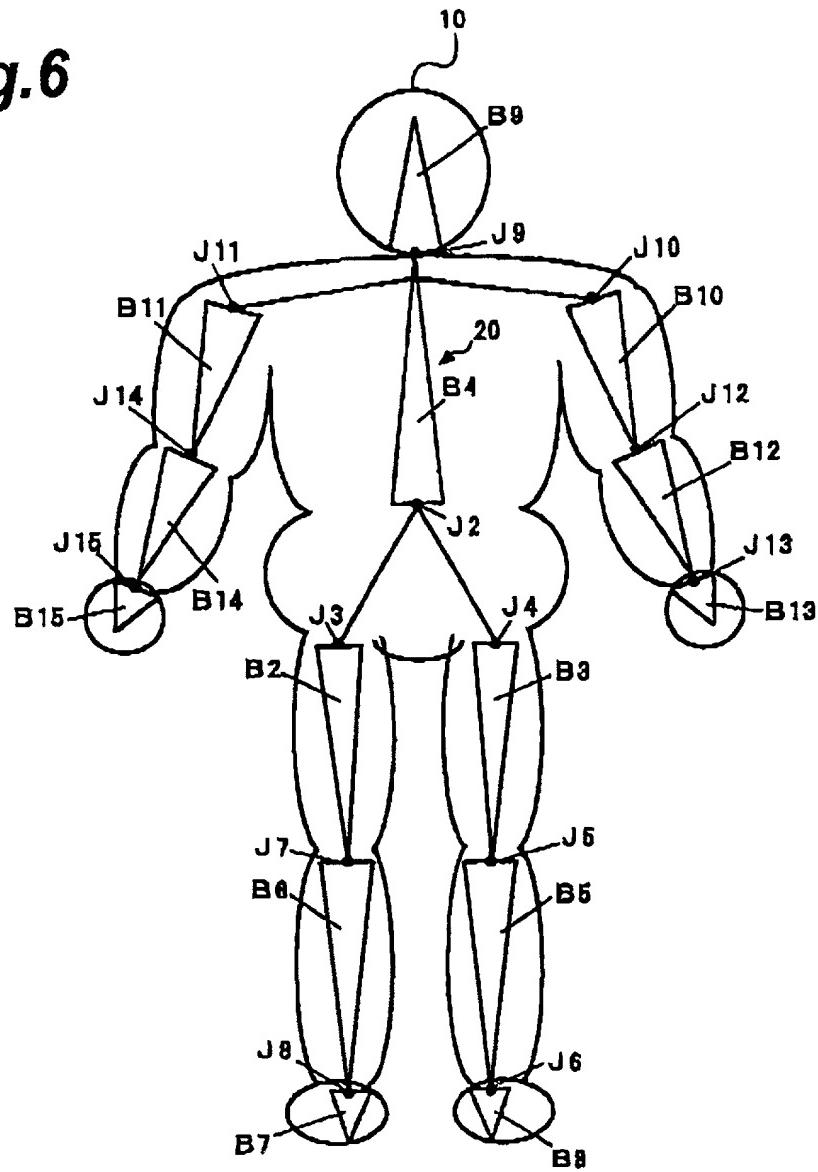
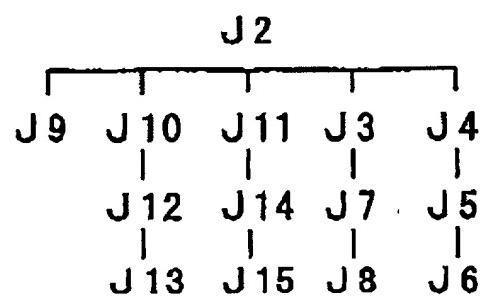
510	NUMBER OF GROUPS	3
520	NUMBER OF MEMBERS	4
530	VERTEX	vtx1
530	WEIGHT	(540)
530	1.0	NUMBER OF NORMALS(570)
530	2	NORMALS(591)
530	nml0	nml1
532	VERTEX	vtx2
532	WEIGHT	(542)
532	1.0	NUMBER OF NORMALS(572)
532	1	NORMALS(592)
532	nml10	
534	VERTEX	vtx3
534	WEIGHT	(544)
534	1.0	NUMBER OF NORMALS(574)
534	1	NORMALS(593)
534	nml2	
536	VERTEX	vtx4
536	WEIGHT	(546)
536	1.0	NUMBER OF NORMALS(576)
536	2	NORMALS(594)
536	nml3	nml1
522	NUMBER OF MEMBERS	4
550	VERTEX	vtx5
550	WEIGHT	(560)
550	0.5	NUMBER OF NORMALS(580)
550	1	NORMALS(595)
550	nml11	
552	VERTEX	vtx6
552	WEIGHT	(562)
552	0.5	NUMBER OF NORMALS(582)
552	1	NORMALS(596)
552	nml4	
554	VERTEX	vtx7
554	WEIGHT	(564)
554	1.0	NUMBER OF NORMALS(584)
554	1	NORMALS(597)
554	nml5	
556	VERTEX	vtx8
556	WEIGHT	(566)
556	1.0	NUMBER OF NORMALS(586)
556	3	NORMALS(598)
556	nml6	nml8
556	nml9	
524	NUMBER OF MEMBERS	1
558	VERTEX	vtx7
558	WEIGHT	(568)
558	0.5	NUMBER OF NORMALS(588)
558	1	NORMALS(599)
558	nml7	

VERTEX GROUP 0

VERTEX GROUP 1

VERTEX GROUP 2

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Fig.6**Fig.7**

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Fig.8

600

610	Root index	root
612	Basic parallel movement amount (x, y, z)	(0, 0, 0)
614	Basic Rotation angle (Rx, Ry, Rz)	(0, 0, 90)
616	Number of joints	4
620	Joint index	Joint0
622	Parent index	root
624	Basic parallel movement amount (x, y, z)	(90, 20, 0)
626	Basic Rotation angle (Rx, Ry, Rz)	(0, 0, 135)
628	Number of vertex groups	2
630	Vertex group number	0
632	Vertex group number	2
640	Joint index	Joint1
642	Parent index	Joint0
644	Basic parallel movement amount (x, y, z)	(40, 0, 0)
646	Basic Rotation angle (Rx, Ry, Rz)	(0, 0, 45)
648	Number of vertex groups	1
650	Vertex group number	1

Joint 0

Joint 1

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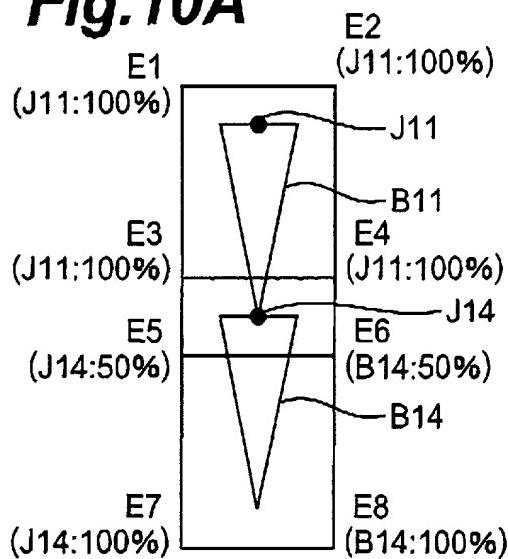
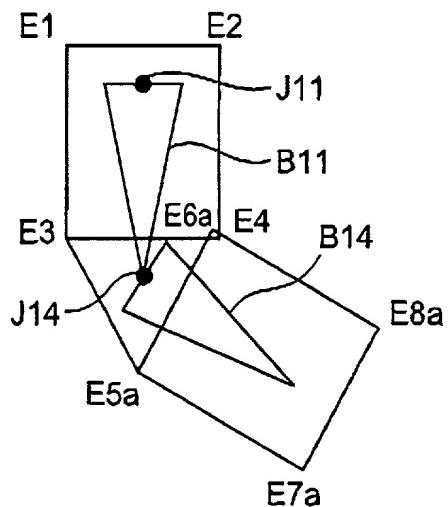
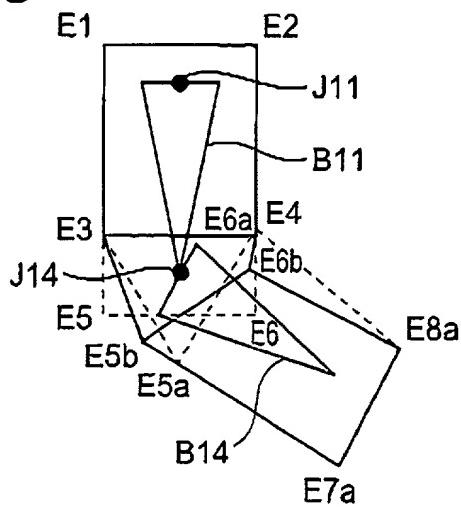
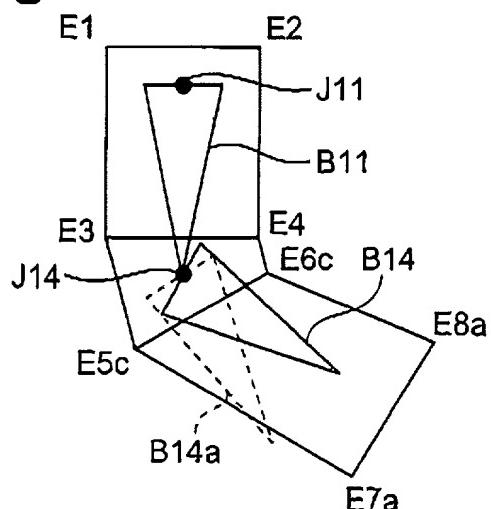
Fig.9A

Number of joints	Number of frames
2	10

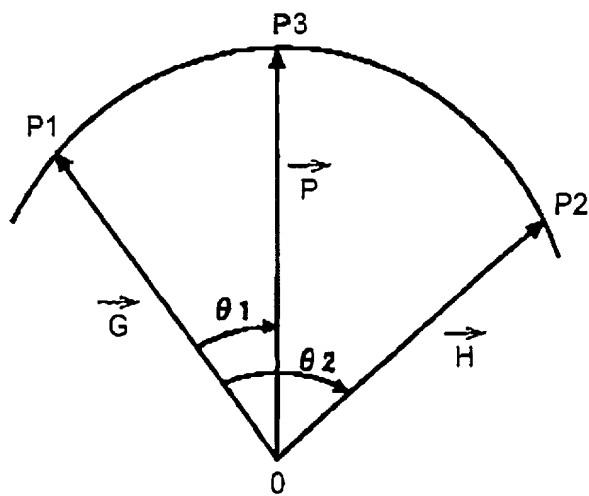
Fig.9B

Joint index	Rotation angle (Rx, Ry, Rz)	Frame
Joint0	(0, 0, 0)	Frame0
Joint1	(0, 0, 0)	
Joint0	(10, 0, 135)	Frame1
Joint1	(-10, 5, 45)	
Joint0	(90, 0, 150)	Frame9
Joint1	(-90, 45, 45)	

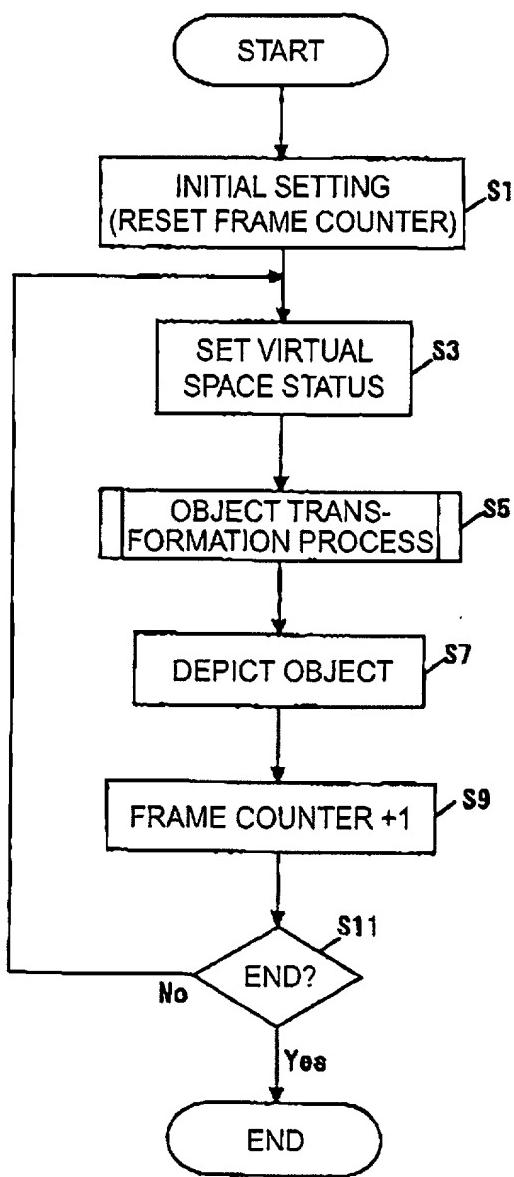
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Fig.10A**Fig. 10B****Fig. 10C****Fig. 10D**

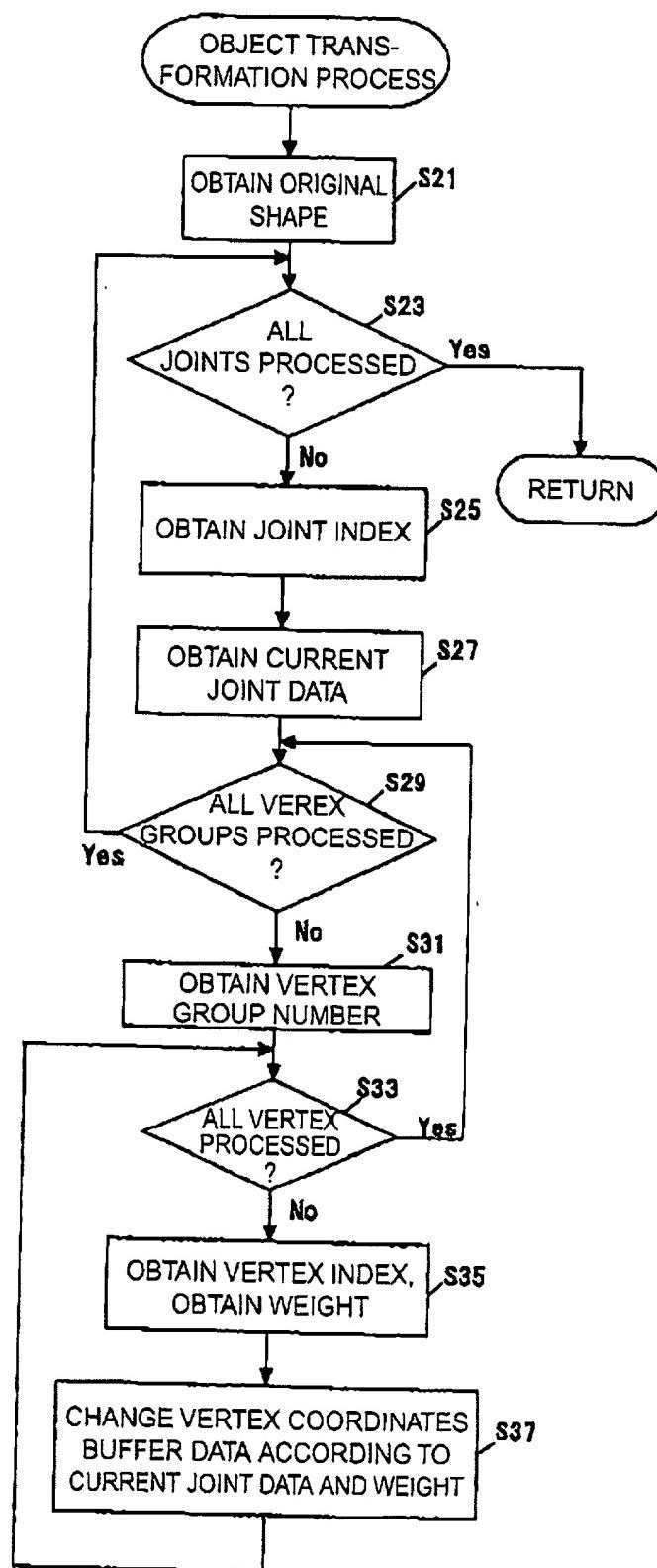
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Fig.11

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Fig.12

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Fig.13

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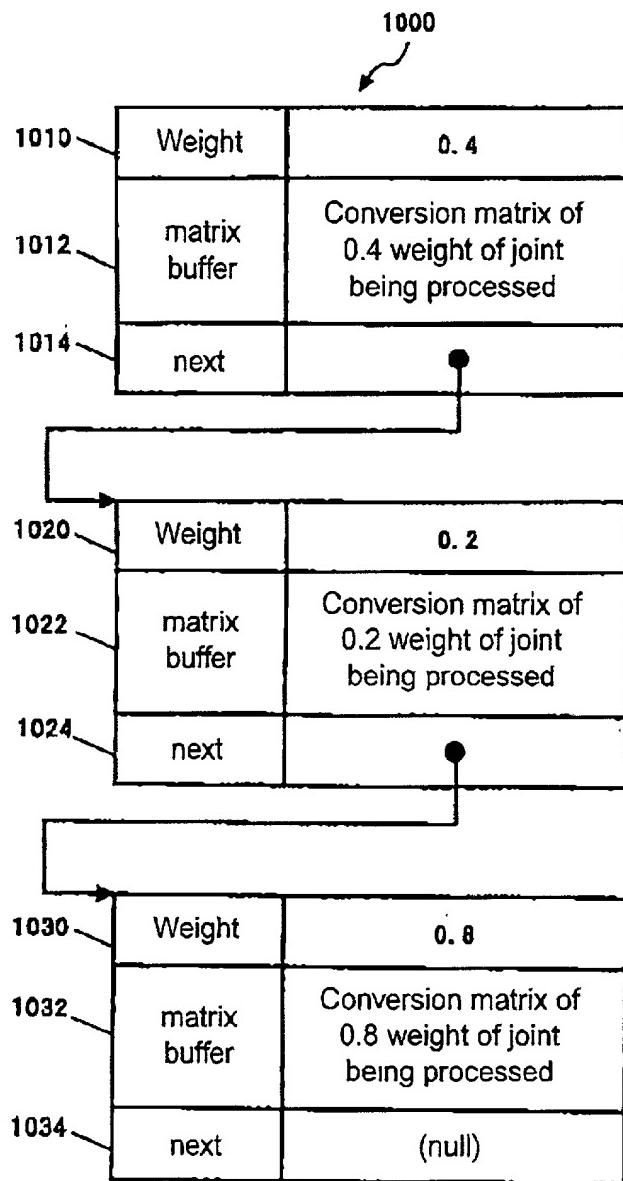
Fig.14

Joint index	Matrix data
root	Root conversion matrix
Joint0	Conversion matrix with 100% weight of joint0
Joint1	Conversion matrix with 100% weight of joint1

Fig.15

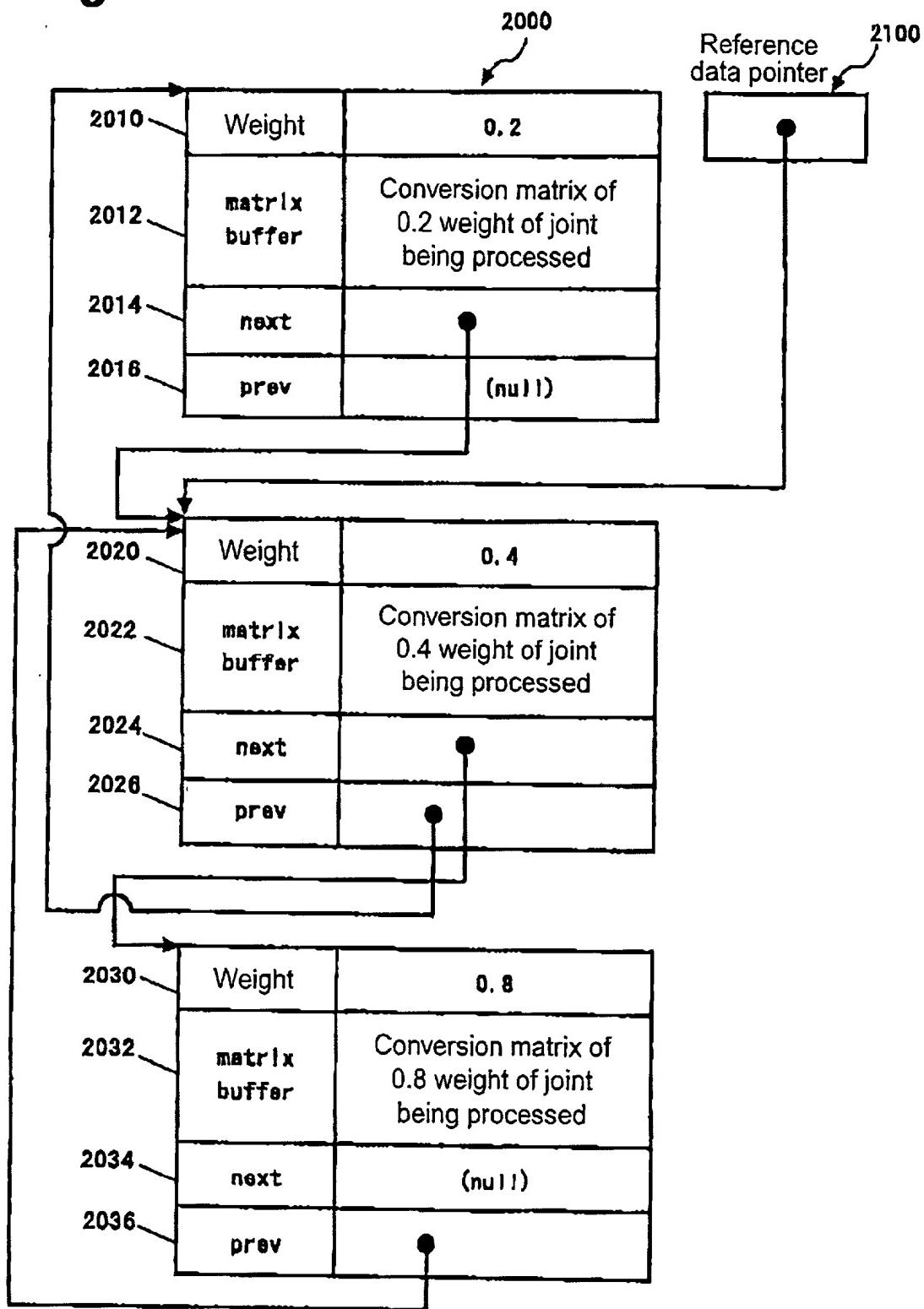
Weight	Weight
matrix buffer	Conversion matrix according to weight of joint being processed

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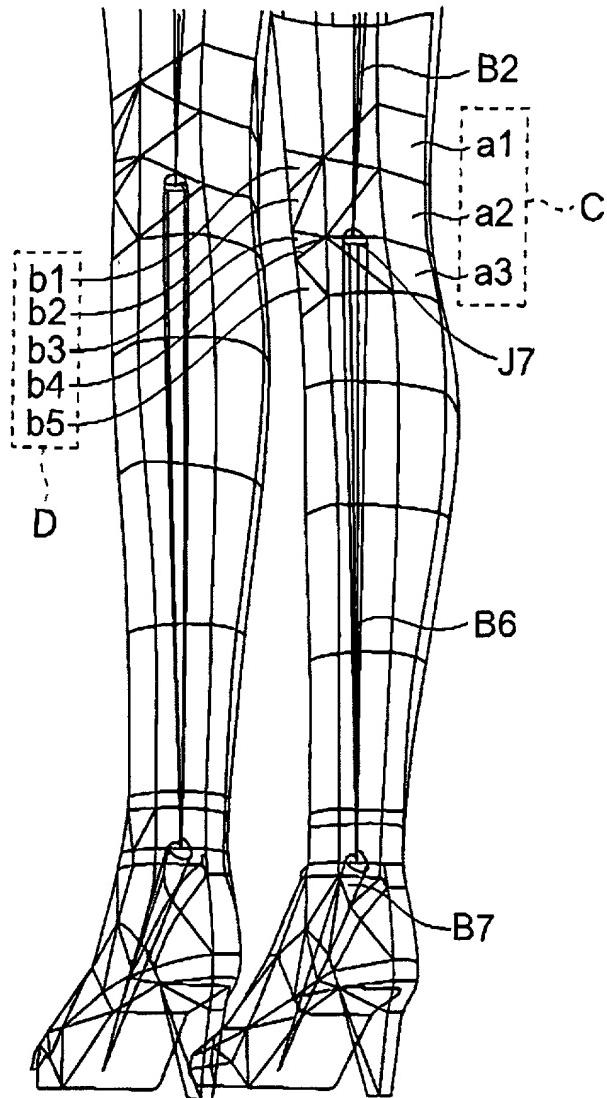
Fig.16

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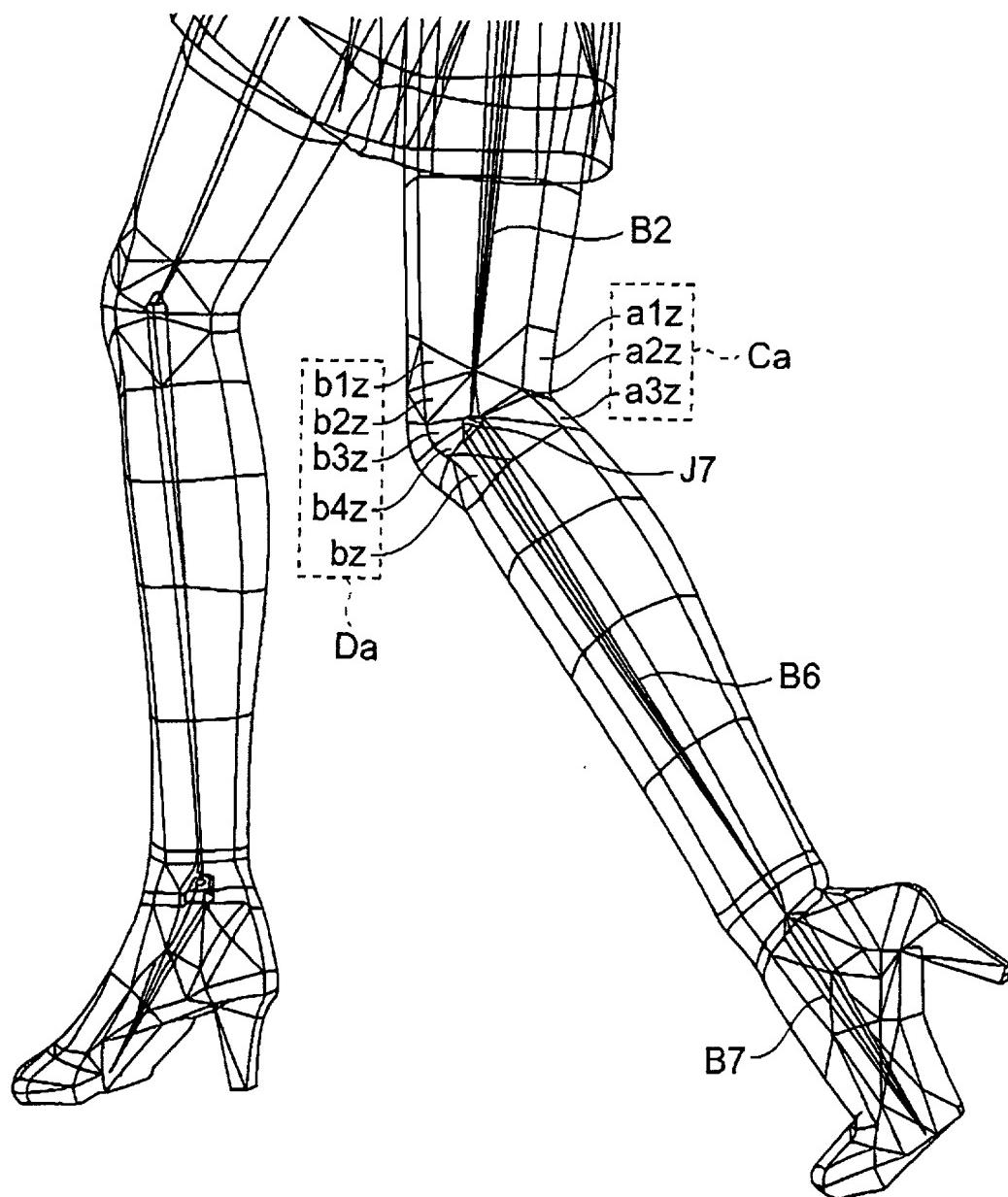
Fig.17



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Fig.18

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Fig.19

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Fig.20



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Fig.21